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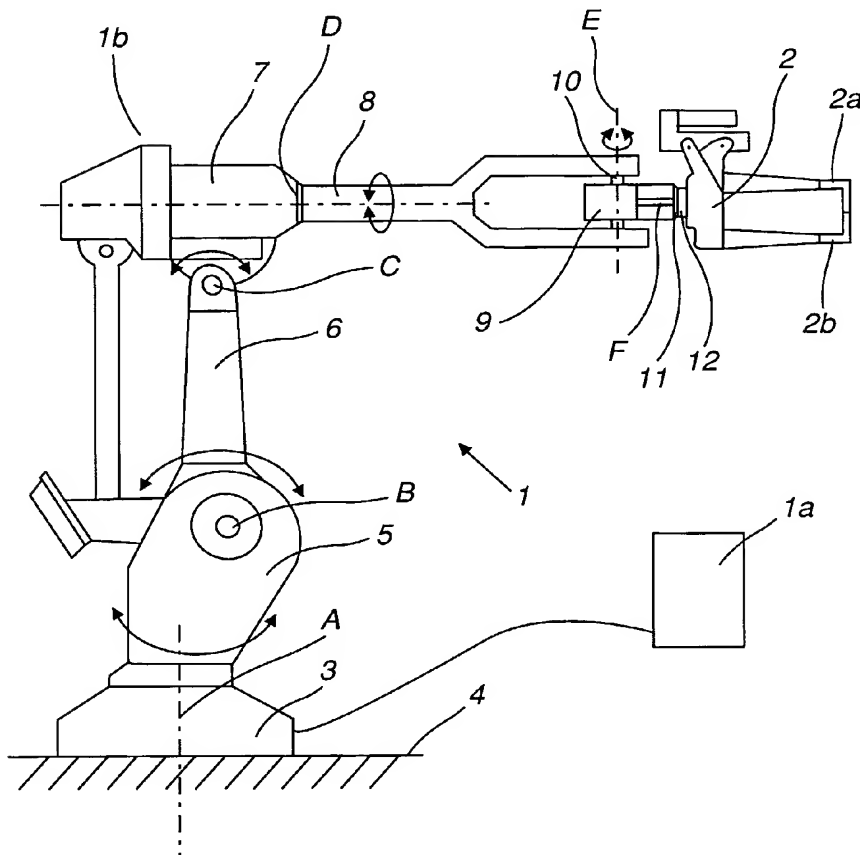
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(54) Title: METHOD IN INFUSTRIAL ROBOT SYSTEM



(57) Abstract: The invention comprises a method of an industrial robot (), comprising a control unit () and a manipulator () including a tool () comprising a defined TCP and a device for determining a distance error (d^*) between an inaccurately programmed position (p_{1p}) for a spot (1) on a surface () of a work piece () and a corresponding actual position (p_{1tu}).

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